ABSTRACT OF THE DISCLOSURE

A vehicular motion control apparatus uses a steering angle detected by a steering angle sensor capable of detecting an absolute rotational angle. This control apparatus has a yaw rate sensor. If a reference rotational position of the steering angle sensor has not been determined, the control apparatus calculates a plurality of target yaw rates on the basis of a plurality of steering angles estimated from a steering angle detected by the steering angle sensor, and controls motion of a vehicle on the basis of the minimum one of differences between the target yaw rates and an actual yaw rate. The control apparatus determines a reference rotational position of the steering angle sensor on the basis of a steering angle corresponding to the minimum one of the differences, and then calculates a steering angle for motion control on the basis of the detected steering angle and the determined reference rotational position.